





Projector intrinsics are known and static | Camera intrinsics known and static Relative position and orienation of camera and projector to each other is known and static | Display surface is flat 49 State FIG. 3 Not Calibrated Action: (Calibration) { Projector: display points observe points *see newTechnique txt* { camera: { Computation: use correspondences to compute homography between camera and projector Then use this, along with the pre-computed/measured information, to compute the "correcting warp" 7 State Calibrated Action: (Verify Calibration) Use whatever!s being displayed; and the Computation: homography between camera and projector to generate prediction of what camera should see observe: whatever is being displayed. Camera Computation: Compare predicted and observed images Predicted and Observed Images Similar?

